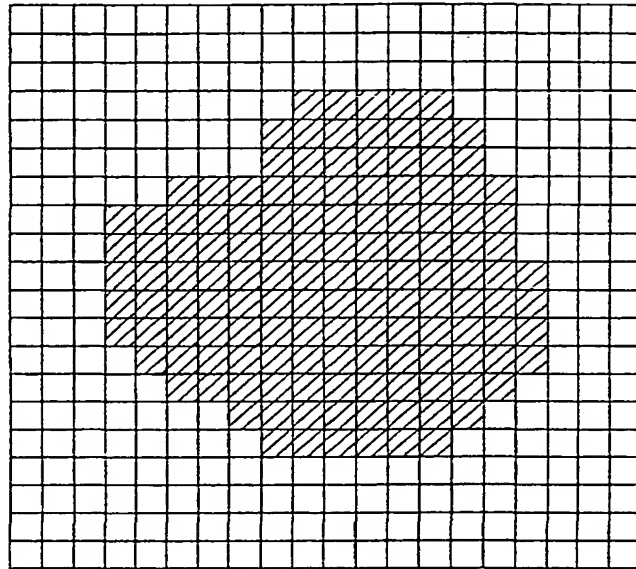


# FIG. 1

(a) THREE-DIMENSIONAL BIT-MAP



(b) SOLID SHAPE DESCRIBING METHOD  
OF THE PRESENT INVENTION

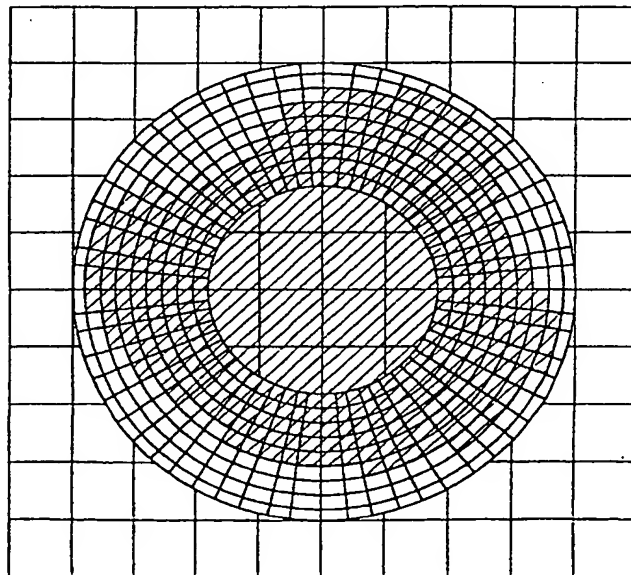


FIG. 2

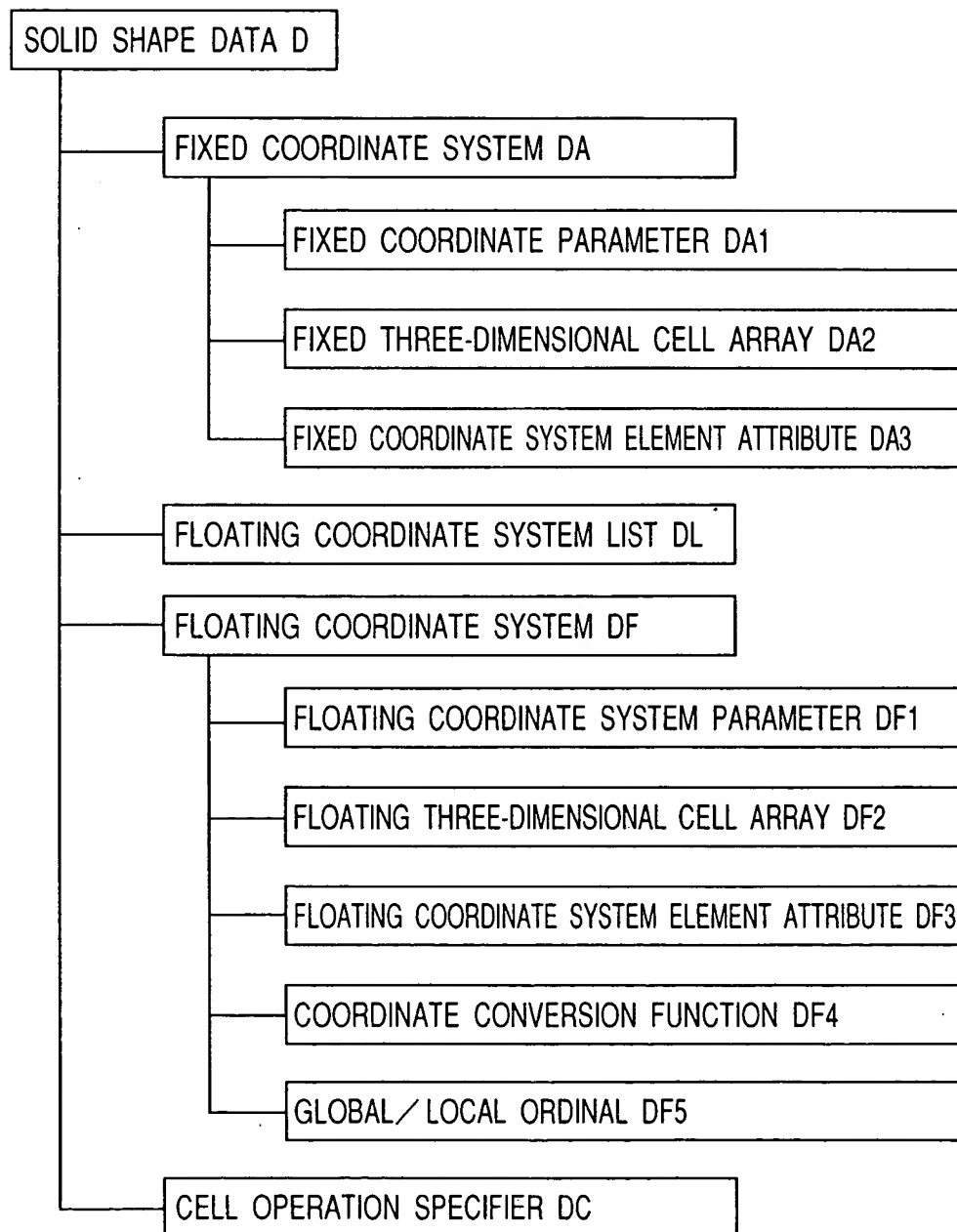


FIG. 3

## COORDINATE PARAMETERS

$$\boxed{r} \quad \boxed{\theta}$$

## THREE-DIMENSIONAL CELL ARRAY

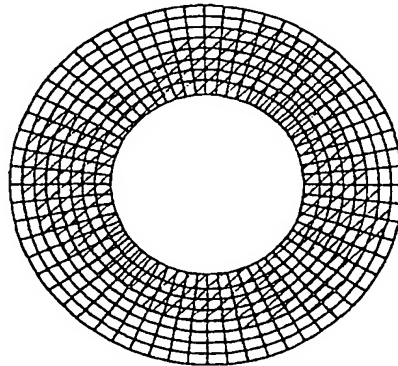
1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	0	1	1
1	1	1	1	1	1	1	1	1	0	...	0	0	0
0	0	0	1	1	1	1	1	0	0	...	0	0	0
0	0	0	0	0	0	0	0	0	0	...	0	0	0

## COORDINATE CONVERSION FUNCTIONS

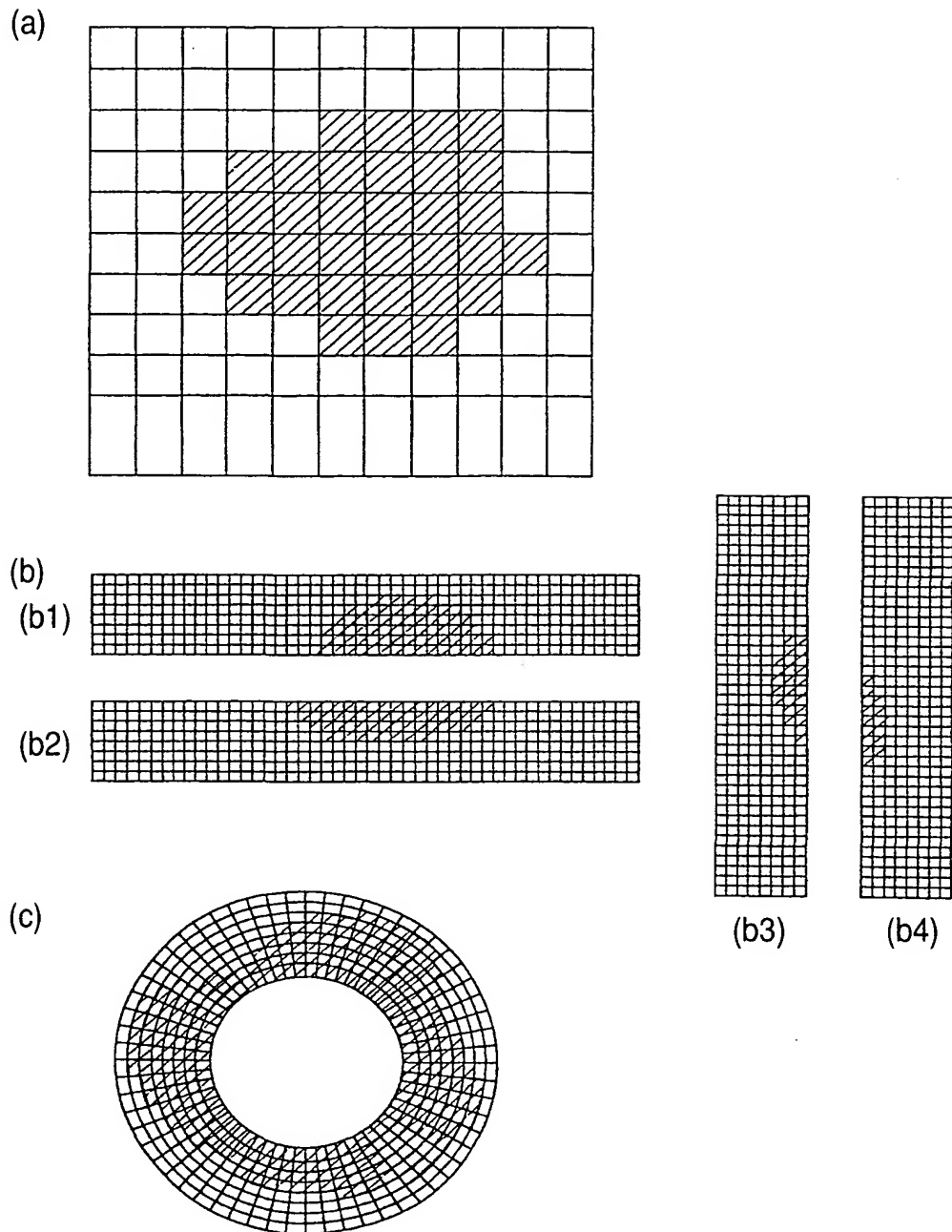
$$X(r, \theta) = r \cos \theta$$

$$Y(r, \theta) = r \sin \theta$$

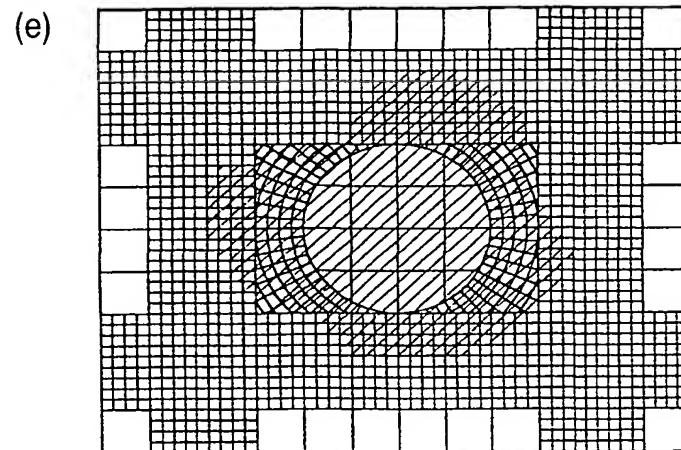
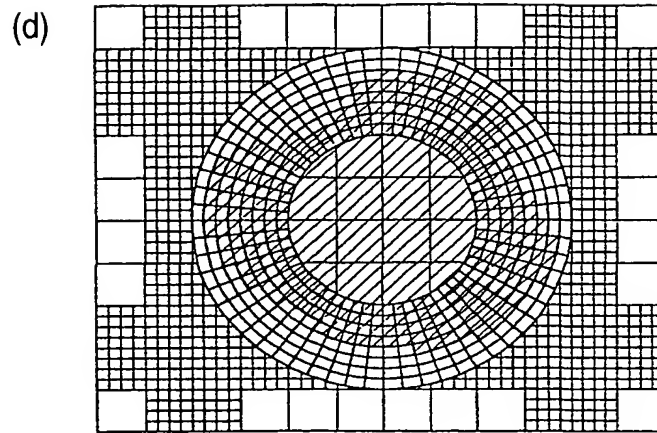
## SOLID SHAPE



**FIG. 4**



*FIG. 5*



*FIG. 6*

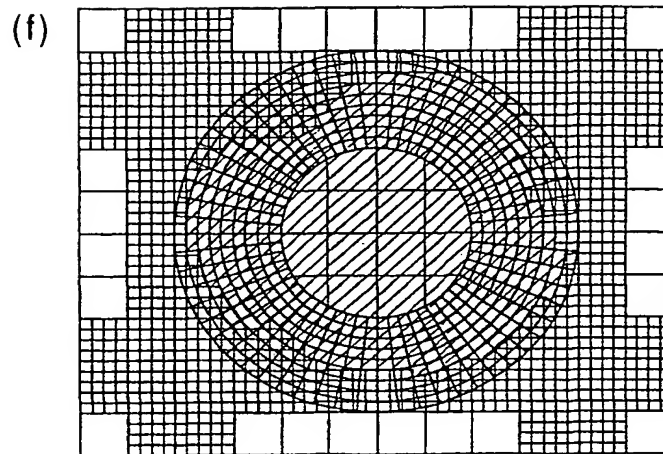


FIG. 7

## SOLID SHAPE REMOTE PROCESSING SYSTEM SA

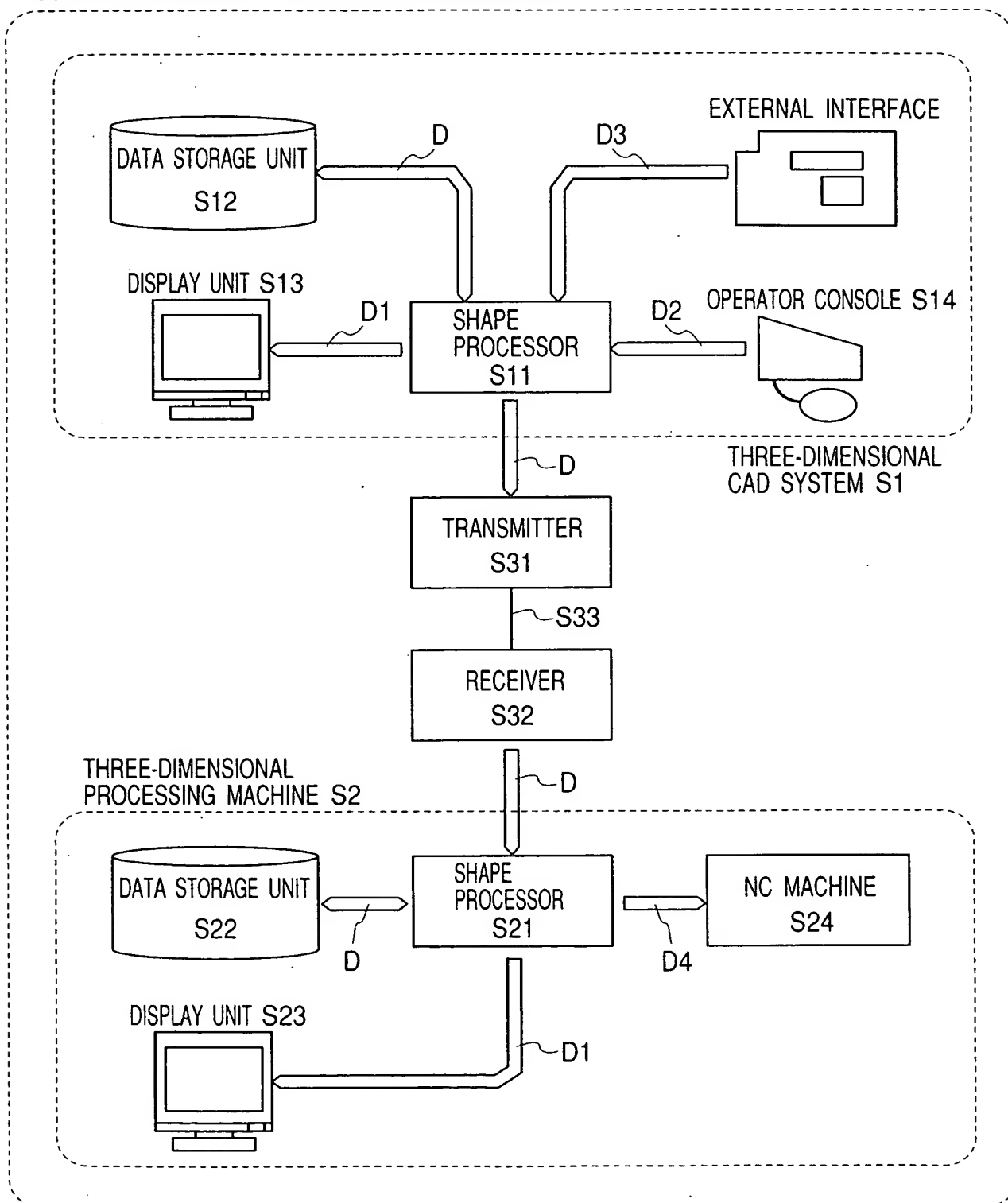
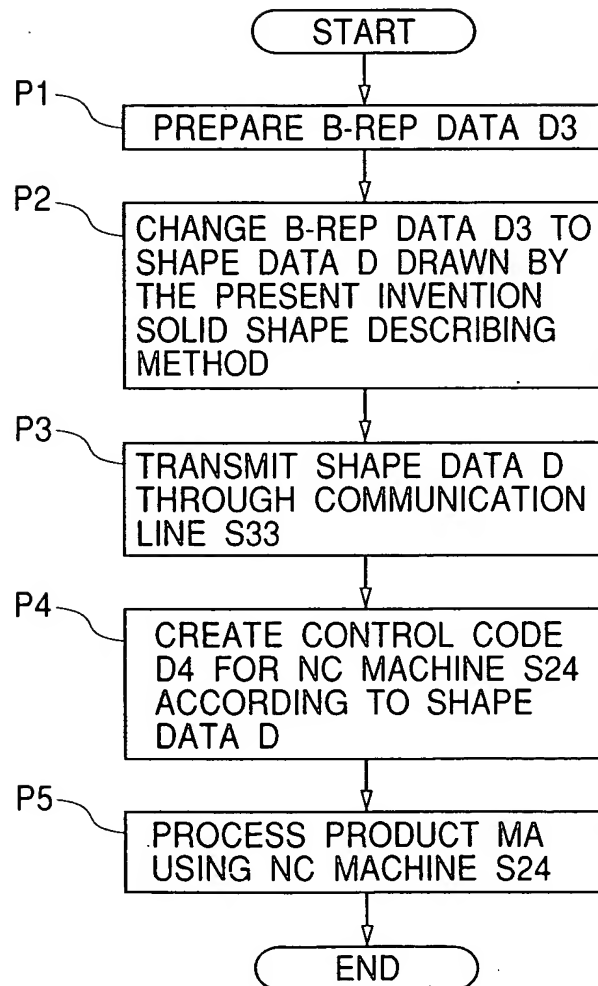
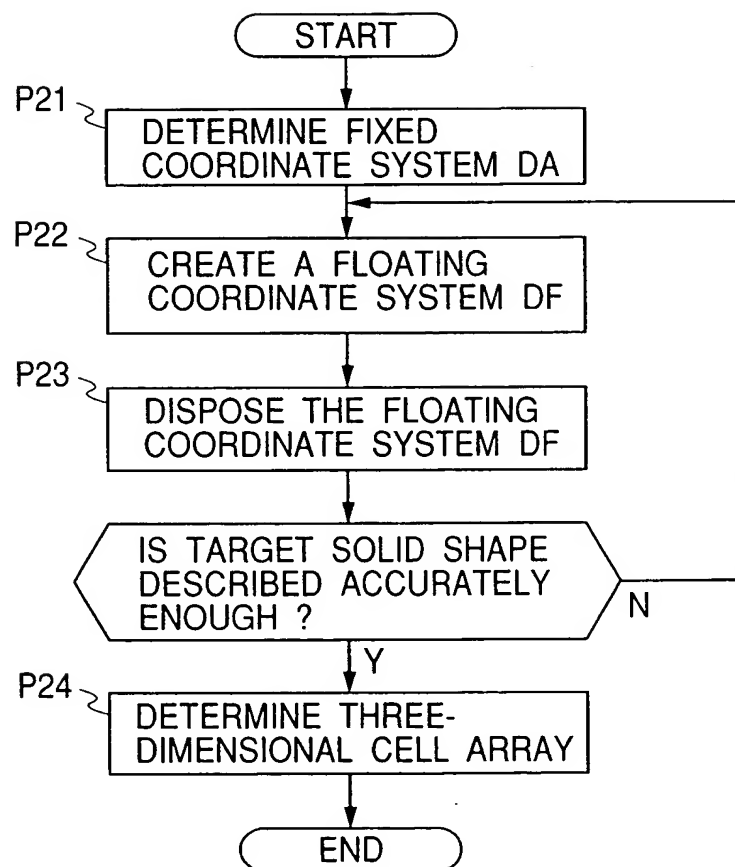


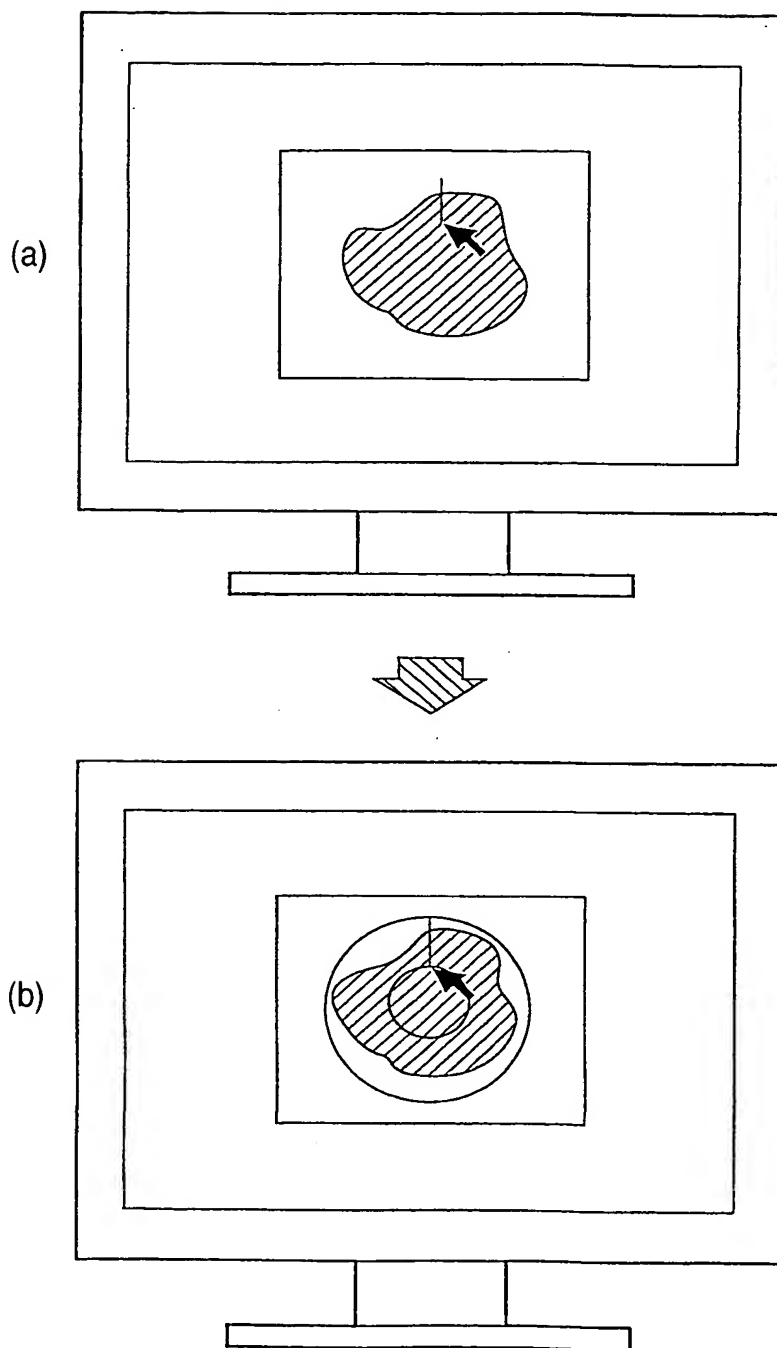
FIG. 8

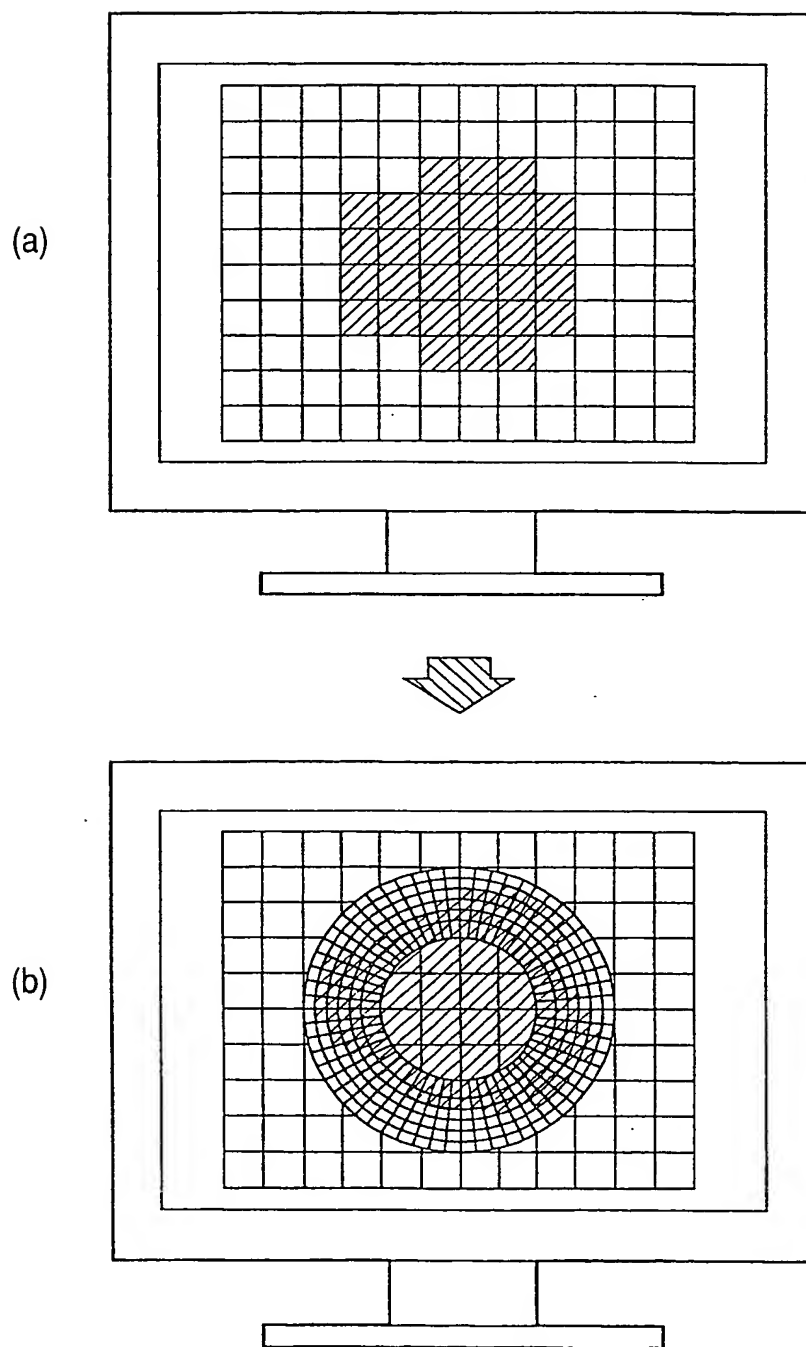




**FIG. 9**

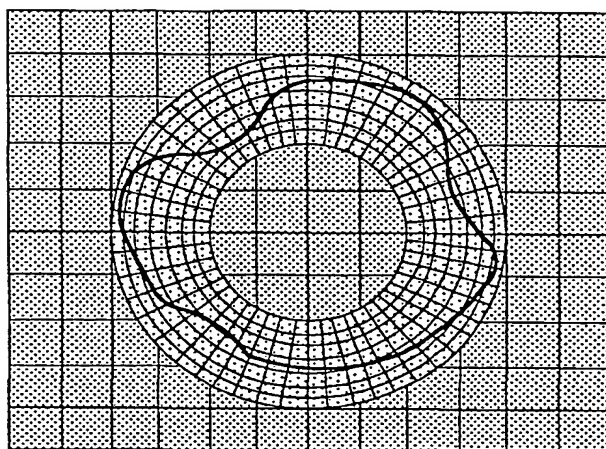
*FIG. 10*



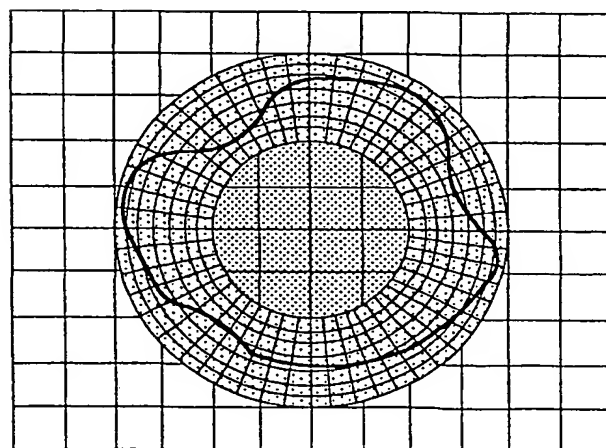
*FIG. 11*

*FIG. 12*

(a)

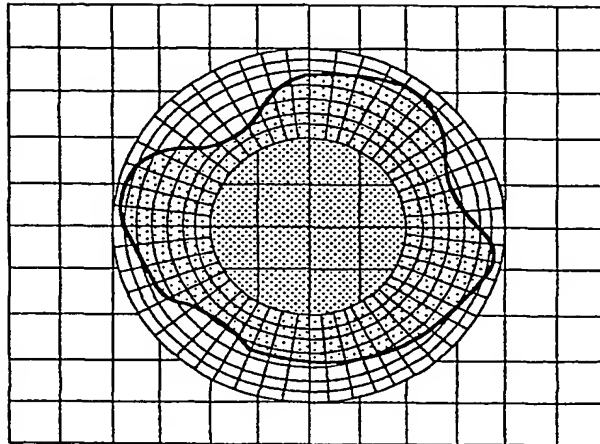


(b)



*FIG. 13*

(c)



*FIG. 14*

## SOLID SHAPE CAD CAM SYSTEM SB

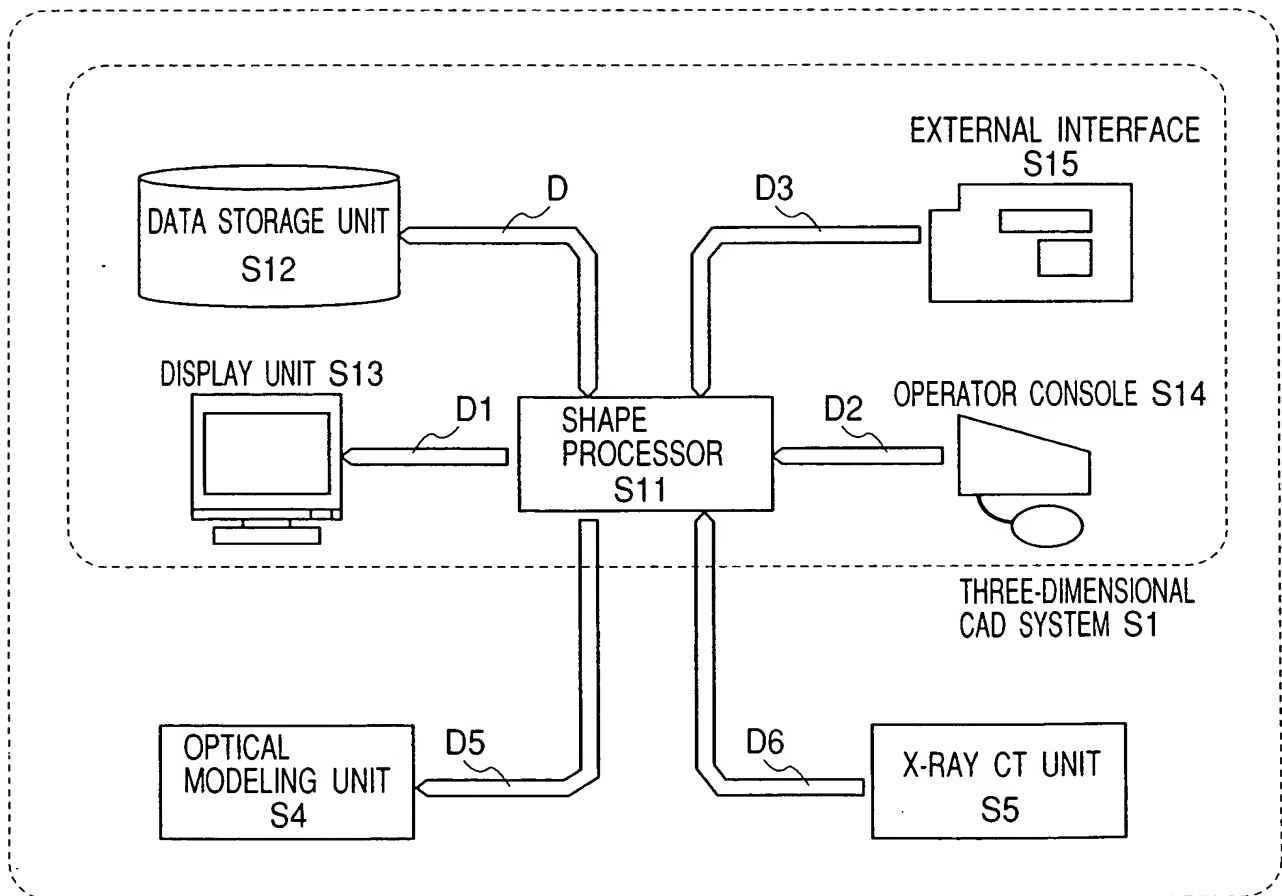


FIG. 15

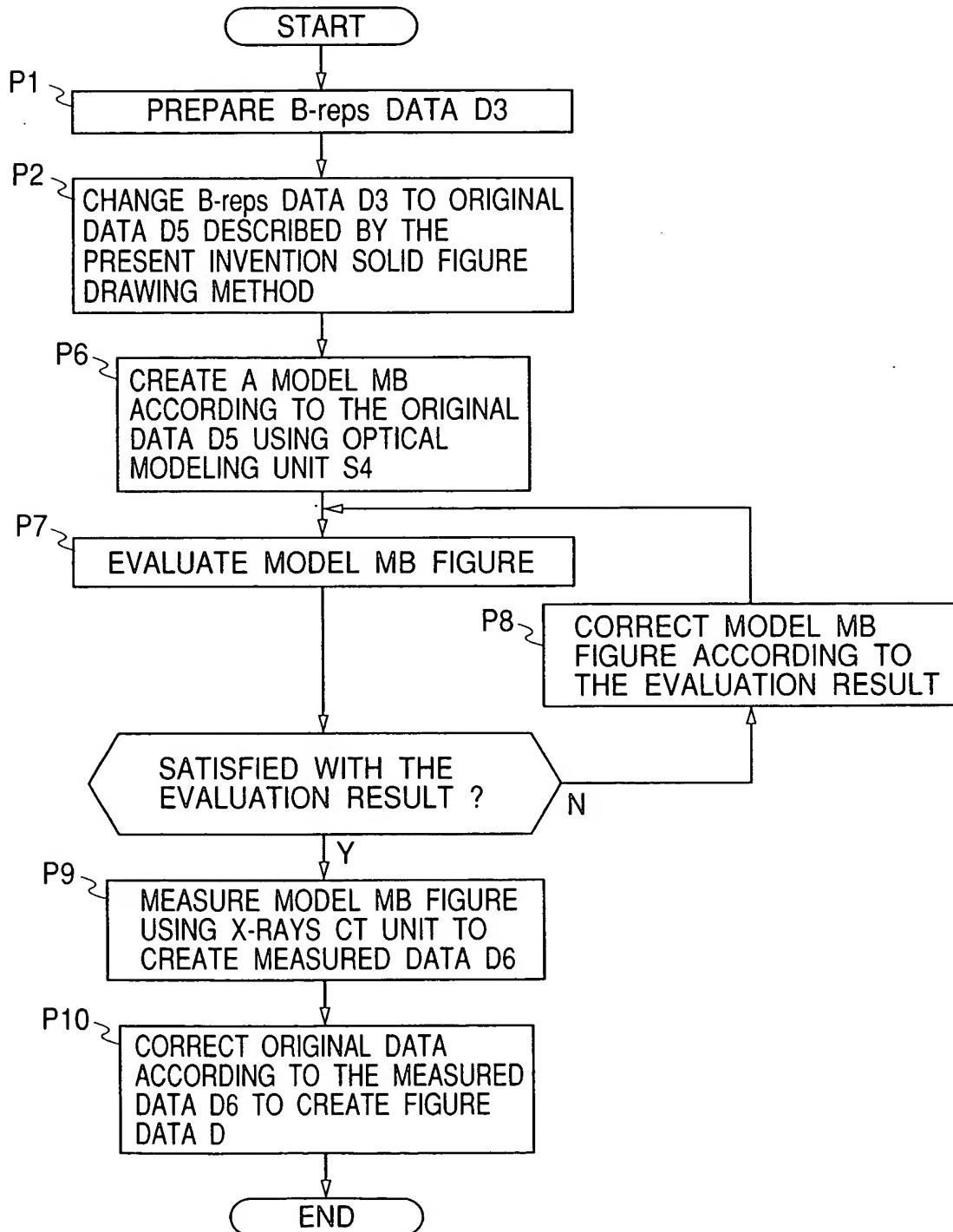
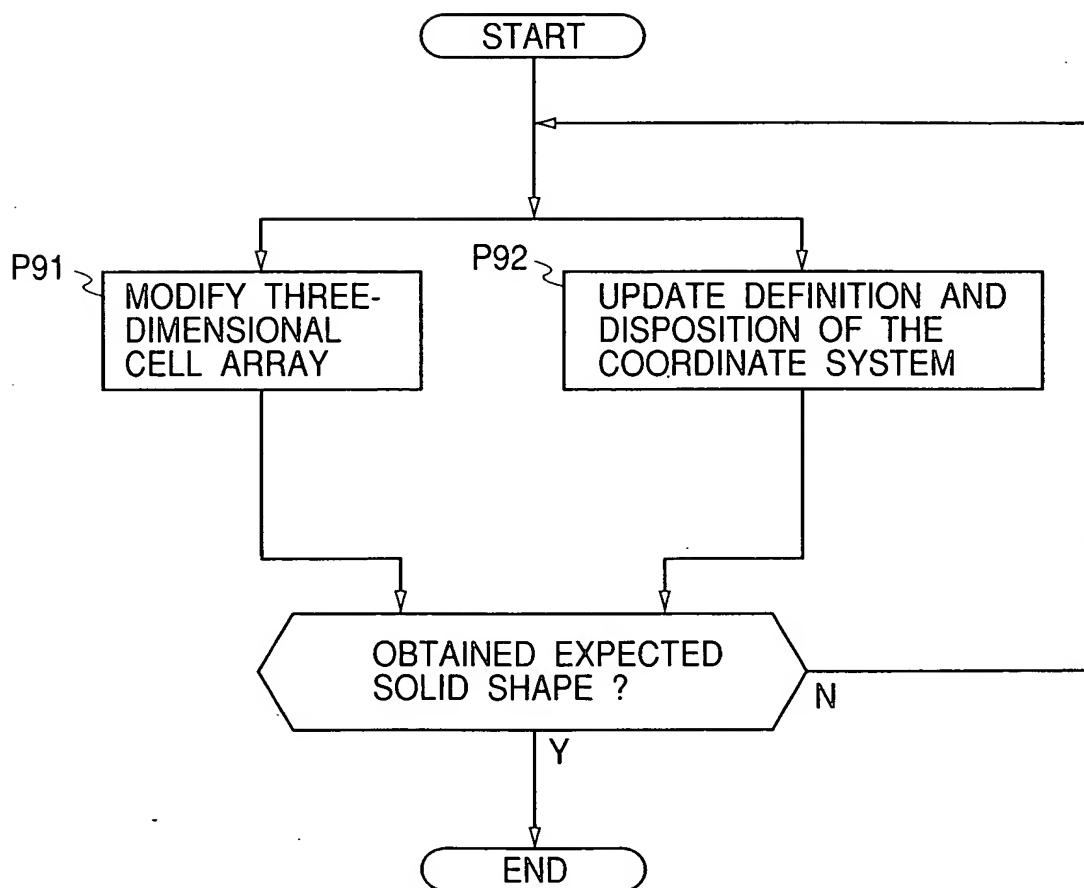
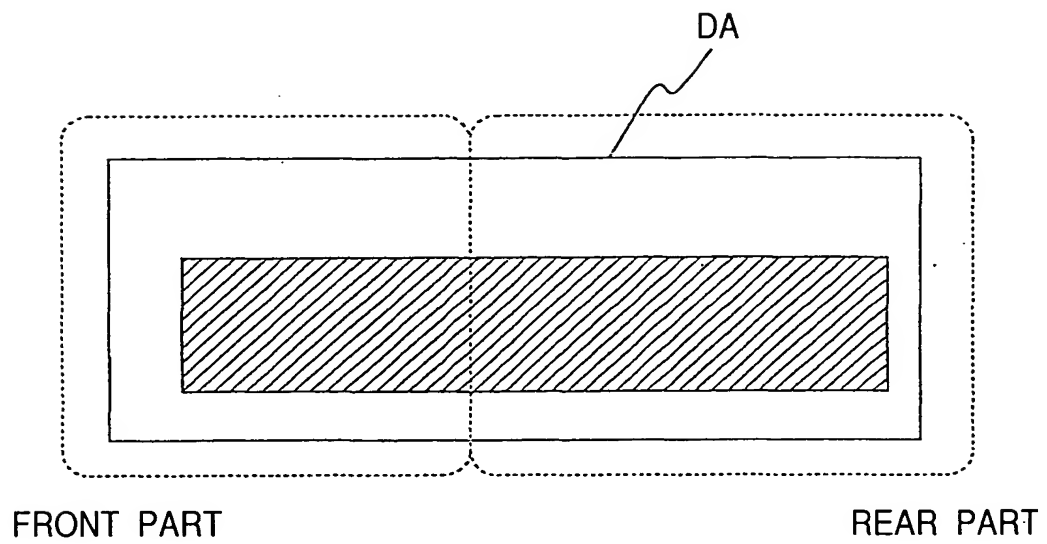


FIG. 16



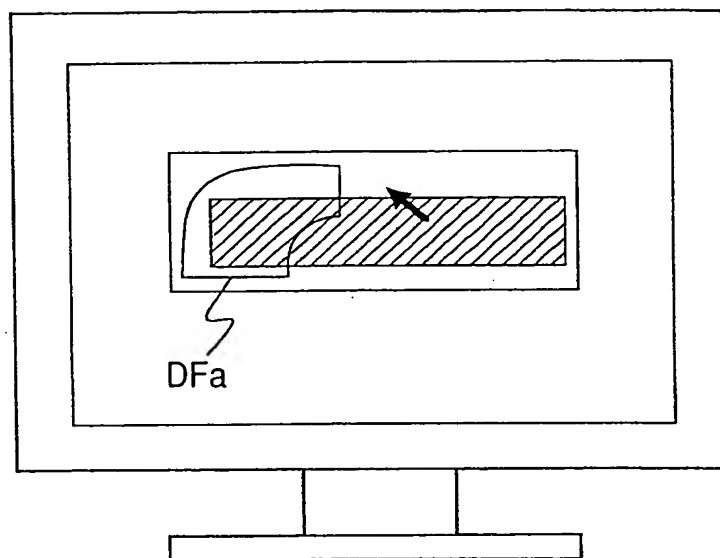


*FIG. 17*

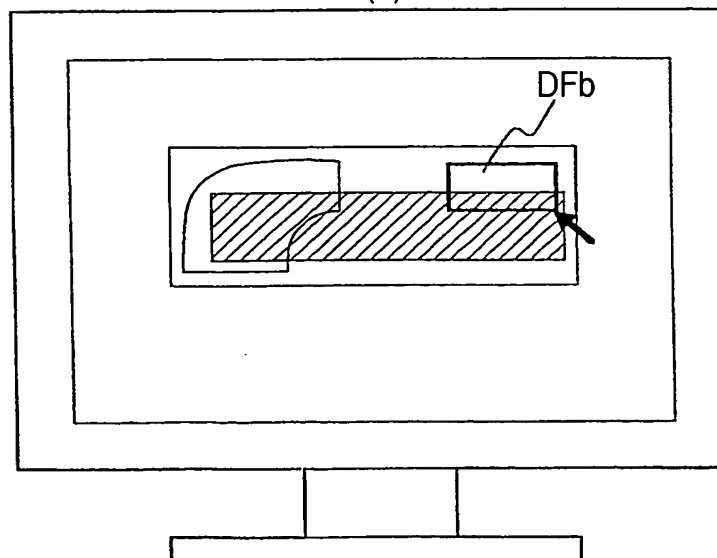


**FIG. 18**

(a)

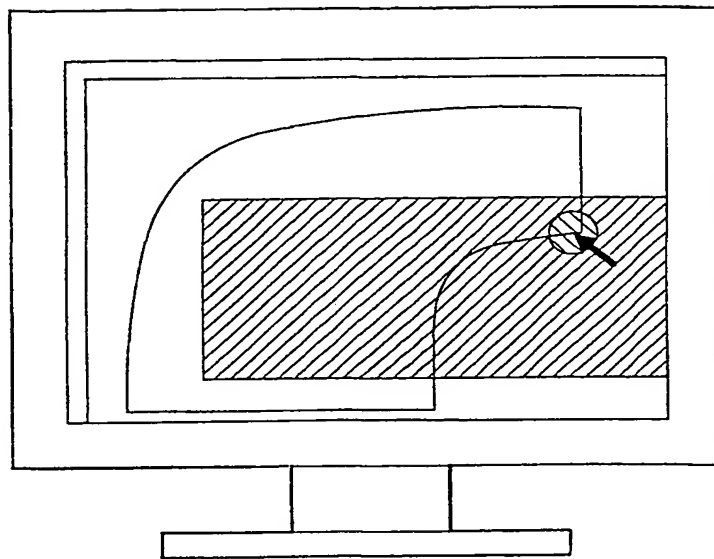


(b)

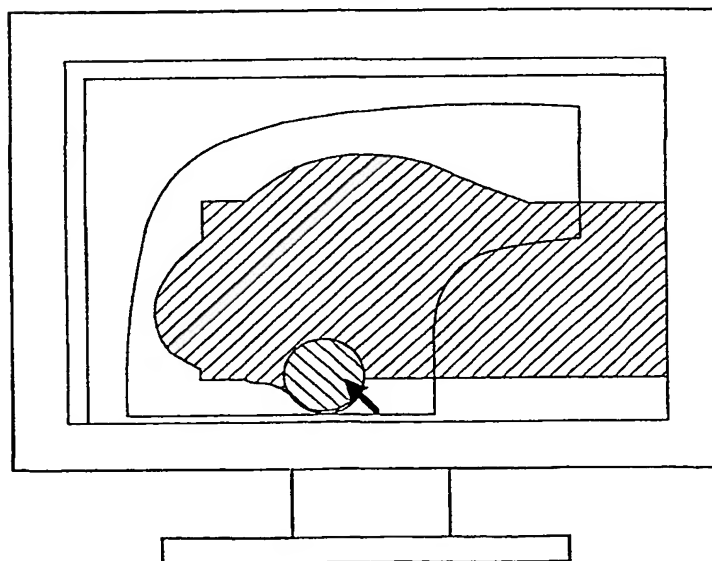


*FIG. 19*

(a)

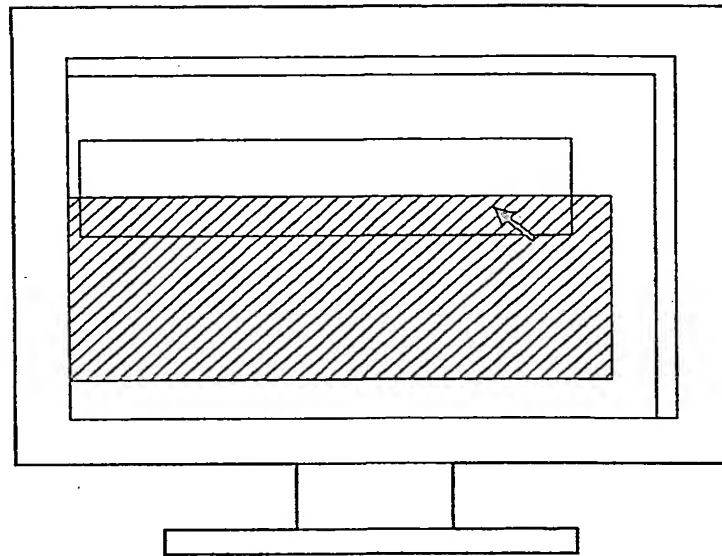


(b)

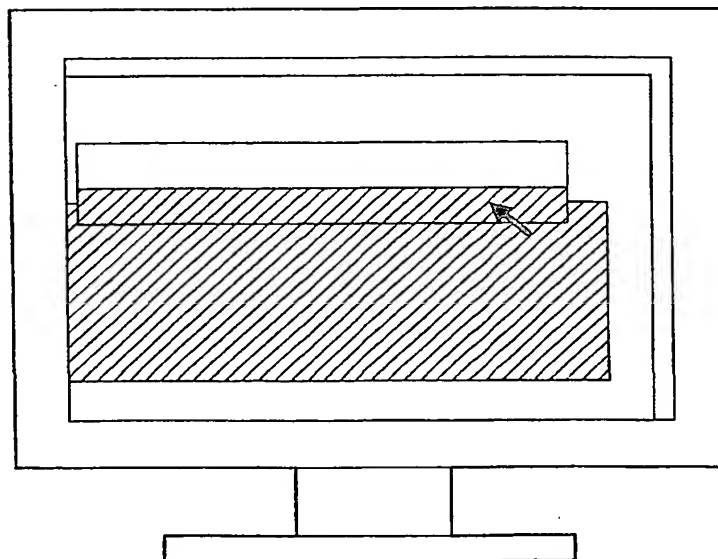


*FIG. 20*

(a)



(b)



*FIG. 21*

